

Abstract

A method for providing control variables ( $a_m$ ,  $a_b$ ) for guiding a motor vehicle as a function of input quantities ( $v$ ,  $e_l$ ,  $e_k$ ,  $d_i$ ,  $v_{ri}$ ,  $\phi_i$ ), which represent the traffic situation, and as a  
5 function of dynamically changeable parameters, characterized in that a single evaluation quantity ( $g$ ) is formed from a set of a plurality of input quantities and a plurality of the parameters are determined on the basis of the same evaluation quantity.

10 Figure 1